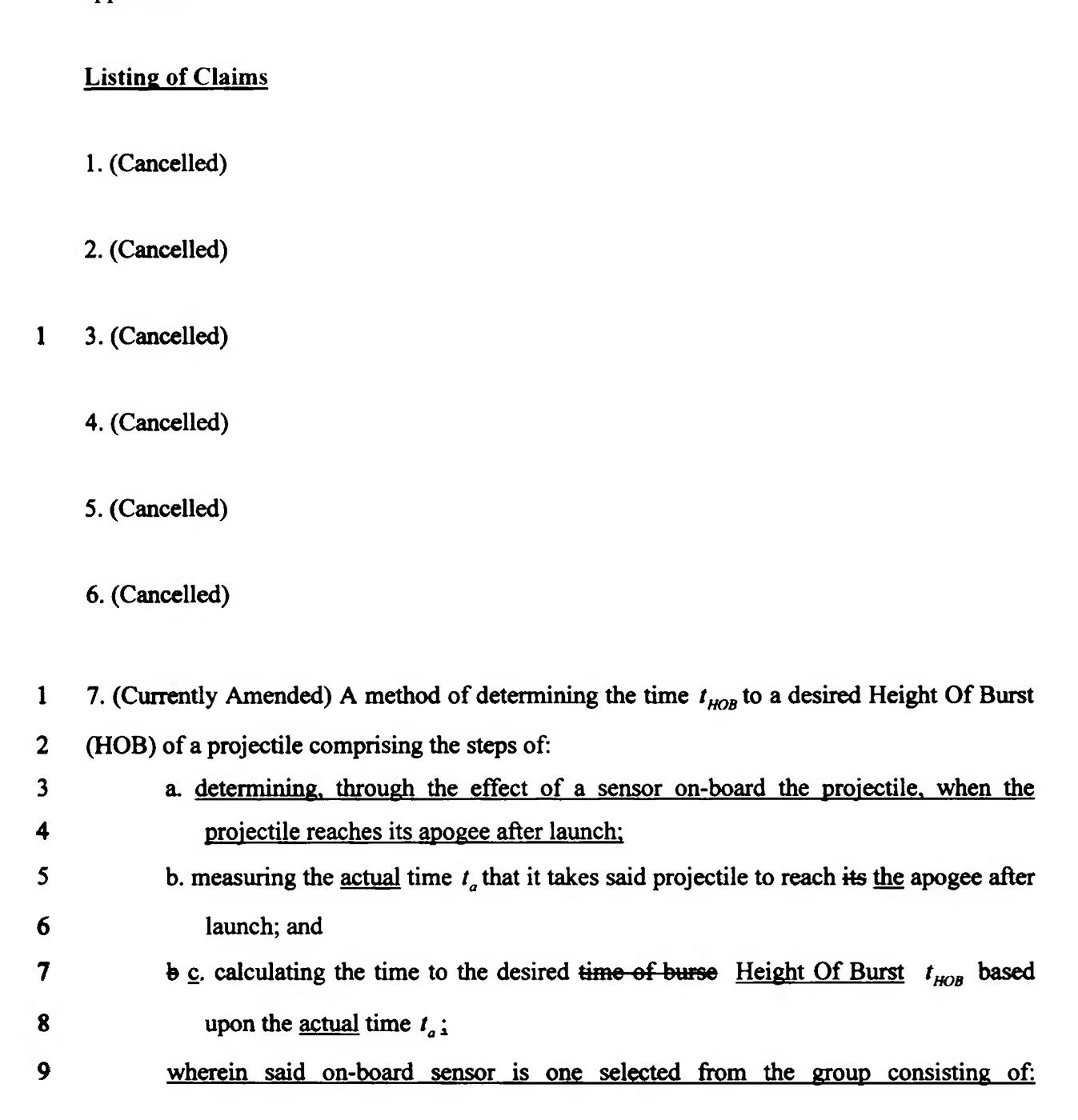
## Amendments to the Claims

This listing of claims will replace all the prior revisions, and listings of claims in this application.



- 10 <u>accelerometric sensor, gyroscopic sensor, velocity sensor, global positioning</u>
  sensor, inertial sensor, and MEMs.
  - 8. (Currently Amended) The method of claim 7 wherein the calculating step b c above
- 2 comprises setting the  $t_{HOB}$  as a percentage X% of  $t_a$  wherein said percentage is less than
- 3 100% and wherein  $t_{HOB} = t_a + X\%t_a$
- 9. (Previously Presented) The method of claim 8 wherein said percentage of  $t_a$  is calculated
- 2 as follows:
- if  $t_a > 12$  seconds then down leg time = 90% of  $t_a$ ;
- 4 if  $12 \sec > t_a > 9$  seconds then down leg time = 70% of  $t_a$ ;
- if  $9 \sec > t_a > 7$  seconds then down leg time = 10% of  $t_a$ ;
- if  $t_a < 7$  seconds then there may be a malfunction and the projectile should be
- disabled.
- 1 10. (Currently Amended) The method of claim 7 wherein said step b c is calculated as
- 2 follows:

$$t_{HOB} = t_a + \sqrt{t_a^2 - 2 \times HOB/g + C}$$

- 4 where  $g=9.81 \text{ m/sec}^2 = 32 \text{ ft/sec}^2$
- 5 and C = correction factor.
  - 11. (Previously Presented) The method of claim 10 wherein said correction factor C is
- 2 calculated as follows:
- if  $t_a > 12$  seconds then C = 1.0 sec;
- 4 if  $12 \sec > t_a > 9$  seconds then C =0.75 sec;
- if  $9 \sec > t_a > 7$  seconds then  $C = 0.5 \sec$ ;

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if  $t_a < 7$  seconds then there may be a malfunction and the projectile should be disabled.